

In the Claims:

Please amend the claims as follows:

1. (currently amended) A wrist unit, intended to be connected to a robot arm in an industrial robot, the wrist unit comprising:

a wrist housing,

a wrist ~~part/tilt~~ part forming a tilt pivotally journalled in the wrist housing for rotation about ~~a fifth~~ an axis of rotation of the tilt,

a turn disc rotatably journalled in the ~~wrist part/the~~ tilt for rotation about ~~a sixth~~ an axis of rotation of the turn disc, wherein the ~~sixth~~ axis of rotation of the turn disc is configured to ~~cross~~ be perpendicular to the axis of rotation of the tilt,

a first transmission configured to transmit rotation to the tilt about the ~~fifth~~ axis of rotation ~~to the wrist part/the~~ of the tilt, and

a second transmission configured to transmit rotation to the turn disc about the ~~sixth~~ axis of rotation ~~to~~ of the turn disc, wherein the second transmission comprises a drive-shaft tube arranged symmetrically along the symmetry axis of the wrist housing, the drive-shaft tube is configured to form a continuous channel, the channel is configured to receive and accommodate continuous cabling.

2. (currently amended) The wrist unit according to claim 1, further comprising:

at least one drive means is arranged for driving one of the transmission.

3. (previously amended) A robot arm comprising a module in the form of a wrist unit according to claim 1.

4. (currently amended) The wrist unit according to claim 1, wherein the ~~wrist part/the~~ tilt is journalled in double-sided bearings.

5. (currently amended) The wrist unit according to claim 1, wherein the ~~wrist part/the~~ tilt is journalled in a single-sided bearing.

6. (currently amended) An industrial robot, comprising:

a control system and

a manipulator comprising a robot arm and a wrist unit, arranged on the robot arm, said wrist unit comprising a wrist housing arranged for rotation about ~~a fourth~~ an axis of rotation of the wrist housing, a wrist ~~part/tilt~~ part forming a tilt pivotally journalled in the wrist housing for rotation about ~~a fifth~~ an axis of rotation of the tilt, and a turn disc rotatably journalled in the ~~wrist part/the~~ tilt for rotation about ~~a sixth~~ an axis of rotation of the turn disc, wherein the ~~sixth~~ axis of rotation of the turn disc is configured to ~~intersect the fifth~~ be perpendicular to the axis of rotation of the tilt, the wrist housing further comprising a first transmission configured to transmit rotation from a first drive means to the tilt for rotation about the ~~fifth~~ axis of rotation of the tilt, and a second transmission configured to transmit rotation from a second drive means to the turn disc for rotation about the ~~sixth~~ axis of rotation of the turn disc, wherein the ~~first~~ second transmission comprises a drive-shaft tube arranged symmetrically along the ~~fourth~~ axis of rotation of the wrist housing, the drive-shaft tube is configured to form a continuous channel, and

wherein cabling is arranged drawn through the channel, through the ~~wrist part/the~~ tilt and is secured to the turn disc ~~that at least one section of the cabling is radially fixed to the second drive shaft tube.~~

7. (previously amended) The industrial robot according to claim 6, wherein the robot arm comprises at least one drive means.

8. (previously amended) The industrial robot according to claim 6, wherein the drive means are arranged inside the robot arm.

9. (previously amended) The industrial robot according to claim 6, wherein the drive means are arranged on the robot arm.

10. (previously amended) The industrial robot according to claim 6, wherein the wrist unit comprises at least one drive means.

11. (currently amended) A method in an industrial robot with a control system and a manipulator comprising a robot arm, the method comprising: ~~and~~

providing a wrist unit, arranged on the robot arm, said wrist unit comprising a wrist housing arranged for rotation about ~~a fourth~~ an axis of rotation of the wrist housing that is parallel to a longitudinal axis of the robot arm,

providing a wrist ~~part/tilt~~ part forming a tilt pivotally journalled in the wrist housing for rotation about ~~a fifth~~ an axis of rotation of the tilt, ~~and~~

~~providing~~ a turn disc rotatably journalled ~~on the wrist part/the~~ in the tilt for rotation about ~~a sixth~~ an axis of rotation of the turn disc, wherein the ~~sixth~~ axis of rotation of the turn disc is configured to ~~cross the fifth~~ perpendicular to the axis of rotation of the tilt,

~~providing the wrist housing further comprising~~ a first transmission configured to transmit rotation from a first drive unit ~~means~~ to the tilt for rotation of the tilt about the ~~fifth~~ axis of rotation of the tilt, ~~and~~

~~providing~~ a second transmission configured to transmit rotation from a second drive unit ~~means~~ to the turn disc for rotation of the turn disc about the ~~sixth~~ axis of rotation of the turn disc, wherein the control system controls the first and second drive units, the method comprising:

~~providing bringing the control system to control the first and second drive units such that~~ a gear ratio of 1:1 between a drive-shaft tube included in the first transmission, and the turn disc, ~~is 1:1~~

pivotaly rotating the tilt with the first transmission about the axis of rotation of the tilt,
and

rotating the turn disc with the second transmission about the axis of rotation of the turn disc.

12. (new) The wrist unit according to claim 1, axis of rotation of the tilt is perpendicular to a longitudinal axis of the robot arm.